

AMENDMENTS TO THE CLAIMS

1. (currently amended) A surgical device, comprising:
 - a) an ergonomic handle having an upper portion and a grip portion, the upper portion having a handle aperture formed in a sidewall and accessible by a single finger of a user;
 - b) a finger actuator having an actuating finger receiving portion within and accessible through the handle aperture, the finger receiving portion operable with and a translating shaft that extends in a forward direction from the finger receiving portion, and in a rearward direction from the finger receiving portion beyond the handle aperture along the same axis;
 - e) an elongated tubular portion extending from the ergonomic handle and having a longitudinal axis; and
 - d) a rod functionally disposed within the tubular portion along the longitudinal axis, the rod being directly coupled proximally to the translating shaft of the finger actuator and ~~configured to be coupled~~ distally to a functional end, wherein the finger actuator moves in a non-pivoting, linear manner to directly effectuate an equidistant linear movement of the rod while maintaining a hand of the user about the ergonomic handle in a position consistent with a functional position of the hand.
2. (original) A surgical device as in claim 1, further comprising a functional end coupled to a distal end of the rod, such that bidirectional pressure applied by the single finger to the finger actuator along the longitudinal axis manipulates the functional end in a bidirectional manner in a common direction to the bidirectional pressure.
3. (currently amended) A surgical device as in claim 2, further comprising a ratcheting mechanism supported on the translating shaft to lock the finger actuator in a fixed position, thus locking the functional end in a fixed position.
4. (original) A surgical device as in claim 2, wherein the functional end is free to rotate around the longitudinal axis.

5. (original) A surgical device as in claim 1, wherein the elongated tubular portion is detachable from the ergonomic handle.
6. (original) A surgical device as in claim 1, wherein the ergonomic handle has a shape of a pistol grip.
7. (original) A surgical device as in claim 6, wherein a portion of the pistol grip that is substantially out of line with the longitudinal axis can be manipulated into a position that is substantially in line with the longitudinal axis.
8. (original) A surgical device as in claim 6, wherein a portion of the pistol grip that is substantially out of line with the longitudinal axis is detachable.
9. (original) A surgical device as in claim 2, wherein the functional end is selected from the group consisting of a grasper, scissors, a blade, a laser and a needle holder.
10. (original) A surgical device as in claim 2, wherein the functional end is a grasper.
11. (original) A surgical device as in claim 2, wherein the functional end is scissors.
12. (currently amended) A surgical system operated by a single finger, comprising:
 - a) an ergonomic handle having an upper portion and a grip portion, the upper portion having a handle aperture formed in a sidewall and accessible by a single finger of a user;
 - b) a finger actuator having an actuating finger receiving portion within and accessible through the handle aperture, ~~the finger-receiving portion operable with~~ and a translating shaft that extends in a forward direction from the finger receiving portion, and in a rearward direction from the finger receiving portion beyond the handle aperture along the same axis;
 - e) an elongated tubular portion extending from the ergonomic handle and having a

longitudinal axis, the translating shaft of the finger actuator being positioned substantially in line with the longitudinal axis of the tubular portion; and

Ⓓ a rod functionally disposed within the tubular portion along the longitudinal axis, the rod being directly coupled proximally to the translating shaft of the finger actuator and coupled distally to a functional end, such that bidirectional pressure applied by the single finger to the finger receiving portion of the finger actuator to move the translating shaft in a non-pivoting, linear manner along the longitudinal axis manipulates the functional end in a bidirectional manner in a common direction to the bidirectional pressure.

13. (currently amended) A surgical system as in claim 12, further comprising a ratcheting mechanism supported on the translating shaft to lock the finger actuator in a fixed position, thus locking the functional end in a fixed position.

14. (original) A surgical system as in claim 12, wherein the functional end is free to rotate around the longitudinal axis.

15. (original) A surgical system as in claim 12, wherein the elongated tubular portion is detachable from the ergonomic handle.

16. (original) A surgical system as in claim 12, wherein the functional end is selected from the group consisting of a grasper, scissors, a blade, a laser and a needle holder.

17. (original) A surgical system as in claim 12, wherein the functional end is a grasper.

18. (original) A surgical system as in claim 12, wherein the functional end is scissors.

19. (currently amended) A method of manipulating a surgical instrument with a single finger, comprising the following steps:

a) grasping the surgical instrument with a hand of a user;

- b) inserting the single finger of the user into a finger receiving portion of a finger actuator located within and accessible through a handle aperture of an ergonomic handle of the surgical instrument the finger actuator further comprising a translating shaft that extends in a forward direction from the finger receiving portion, and in a rearward direction from the finger receiving portion beyond the handle aperture along the same axis;
 - e) moving the single finger in a direction away from the hand, causing the finger actuator to move in a non-pivoting, linear manner away from the hand to directly effectuate operation of a functional end while continually maintaining a hand of the user in a functional position about the ergonomic handle; and
 - d) moving the single finger in a direction toward the hand, causing the finger actuator to move in a non-pivoting, linear manner toward the hand to directly effectuate operation of the functional end while further continually maintaining the hand of the user about the ergonomic handle in a position consistent with a functional position of the hand.
20. (previously presented) A method of manipulating a surgical instrument with a single finger as in claim 19, further comprising the step of actuating a rotulator with the single finger to rotate the functional end.
21. (currently amended) A surgical device, comprising:
- a) an ergonomic handle having an upper portion and a grip portion, and a finger receiving portion of a finger actuator disposed within the upper portion and accessible to a single finger of the a grasping hand through a handle aperture formed in a sidewall of the upper portion, the finger actuator further comprising a translating shaft that extends in a forward direction from the finger receiving portion, and in a rearward direction from the finger receiving portion beyond the handle aperture along the same axis;
 - b) an elongated tubular portion extending from the upper portion of the ergonomic handle and having a longitudinal axis, the finger actuator being positioned substantially in line with the longitudinal axis of the tubular portion; and

e) a rod functionally disposed within the tubular portion along the longitudinal axis, the rod being coupled proximally to the finger actuator and ~~configured to be coupled~~ distally to a functional end.